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Patent Claims:

1. Method for controlling a process according to which a need for control is determined depending on a control deviation that is determined by comparing a nominal value with an actual value of a control variable ($\dot{\psi}$),
   c h a r a c t e r i z e d   in that the actual value of the control variable ($\dot{\psi}$) is determined by way of a first process model ($\dot{\psi}_{EST}$) and the need for control (10) is additionally verified by determining control requirements (20, 30, 40) based on values of the control variable ($\dot{\psi}$), being defined by way of additional process models and linked to each other by logical operations.

2. Method as claimed in claim 1,
   c h a r a c t e r i z e d   in that the additional process models are produced with various subsets of a multitude of measured variables (δ, a_{LAT}, v_{REF}, v_{RL}, v_{RR}).

3. Method as claimed in any one or both of claims 1 and 2,
   c h a r a c t e r i z e d   in that a need for control (20) is found out only when there is a need for control (20, 30, 40) for the majority of the additional process models.

4. Method as claimed in any one or more of the preceding claims,
   c h a r a c t e r i z e d   in that an unlimited control intervention being due to the control deviation between the nominal value and the actual value ($\dot{\psi}_{EST}$) determined by way of the first process model is performed only when there is a need for control (20, 30, 40) for all additional process

models.

5. Method as claimed in any one or more of the preceding claims,
   c h a r a c t e r i z e d   in that a control intervention with a reduced duration is performed unless a need for control (20, 30, 40) exists for all additional process models.

6. Method as claimed in any one or more of the preceding claims,
   c h a r a c t e r i z e d   in that a control intervention with a reduced intensity is performed when there is a need for control (20, 30, 40) for all additional process models.

7. Method as claimed in any one or more of the preceding claims,
   c h a r a c t e r i z e d   in that a control intervention is totally suppressed when there is no need for control (20, 30, 40) for any one of the additional process models.

8. Method as claimed in any one or more of the preceding claims,
   c h a r a c t e r i z e d   in that a value of an actuation parameter is modified depending on at least one value of the control variable determined by way of the additional process models.

9. Method as claimed in any one or more of the preceding claims,
   c h a r a c t e r i z e d   in that the process concerns a yaw rate variation in a vehicle.

10. Method as claimed in any one or more of the preceding claims,
    c h a r a c t e r i z e d in that the control variable concerns a yaw rate ($\dot{\psi}$) of the vehicle.

11. Method as claimed in any one or more of the preceding claims,
    c h a r a c t e r i z e d in that a driving situation is determined where control of the driving stability is effected based on the logical operation of the values of the control variable determined by way of the partial models and/or based on the logical operation of these values with predetermined limit values.